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<input type="checkbox"/>	L7	L4 and position error	4
<input type="checkbox"/>	L6	L3 and l4	4
<input type="checkbox"/>	L5	(l3 or L4) and position error	11136
		(5944475   6213853   6213853   6227946   6242879   5833426   6024107   6073828   4854623   4897015   5007784   5429251   5452521   5607276   5613821   5651823   5664925   5746460   5778554   5783834   5789890   5795355   5803979   5810549   5870488   5905850   5954840   5967578   5993142   5993141   6012470   6037733   6059516   6059516   6085670   6121743   6164894   6202482   6205852   6213136   6213136   6256555   6267423   6275748   6283355   6293749   6298280   6326755   6350177   6360144).pn.	
<input type="checkbox"/>	L4		82
<input type="checkbox"/>	L3	(robot\$6 or articulat\$3 or automat\$6 or autonomous\$2 or CNC or machine\$2 or mechanical device or mechan\$6 or servomechan\$4) and position error	11136
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<input type="checkbox"/>	L1	robot and specimen and position error	15

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 Results 1 - 10 of about **614** for "**robot arm**" and "**position error**". (0.42 seconds)

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[\[PDF\] Distributed Digital Control of a Robot Arm](#)

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... outline a system developed for control of a PUMA 560 **robot arm** that uses a ... While operating with a PD control loop, the maximum **position error** (while tracking ...

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[\[PDF\] Positioning a Robot Arm: an Adaptive Neural Approach Introduction](#)

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... perhaps the orientation error is not as important as the **position error** is ... we will present some test results concerning the simulated **robot arm** neural controller ...

[doi.ieeecomputersociety.org/10.1109/NICRSP.1996.542788](http://doi.ieeecomputersociety.org/10.1109/NICRSP.1996.542788) - [Similar pages](#)

[\[PDF\] Microsoft PowerPoint - MLSC\\_Lec1](#)

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... Steady state error Set the torque (u) proportional to the **position error**  $e_K u_p = \dots$  7DOF anthropomorphic **robot arm** SARCOS dexterous arm 7 21 :  $\mathfrak{R} \rightarrow \mathfrak{R}^f \dots$

[www.inf.ed.ac.uk/teaching/courses/mlsc/Notes/Lecture1/MLSC\\_Lec1.pdf](http://www.inf.ed.ac.uk/teaching/courses/mlsc/Notes/Lecture1/MLSC_Lec1.pdf) - [Similar pages](#)

[Remote Robot Control With High Force-Feedback Gain](#)

... n error, which is the difference between the actual position of the **robot arm** and the position commanded by the operator. This **position-error** force-reflection ...

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[Optical Tracking for Telepresence/Teleoperation Space Applications](#)

... The experimental results revealed a **position error** for the shoulder, elbow and wrist of 0.60.6 mm, 0.50 ... "Human Motion Analysis Based on a **Robot Arm** Model," Proc ...

[www.issu.uh.edu/publications/A2001/107-kakadiaris.htm](http://www.issu.uh.edu/publications/A2001/107-kakadiaris.htm) - 25k - [Cached](#) - [Similar pages](#)

[\[PDF\] CS545—Contents I](#)

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... 1979 Japan introduces the SCARA (Selective Compliance Assembly **Robot Arm**); Digital Electronic Automation (DEA) of Turin, Italy ... **position error** (proportional) ...

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[\[PDF\] Resolution , Accuracy, Repeatability, Compliance Resolution ...](#)

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... The sources of **position error** that affect accuracy can be grouped into four ... of representation of resolution, accuracy, and repeatability of a **robot arm** [Kor85 ...

[www.robotics.technion.ac.il/courses/Advanced\\_Laboratory/Lab8/ARL\\_8\\_read.pdf](http://www.robotics.technion.ac.il/courses/Advanced_Laboratory/Lab8/ARL_8_read.pdf) - [Similar pages](#)

[Citations: Model-Based Control of a Robot Manipulator - An ...](#)

... For our robot, a seven DOF anthropomorphic **robot arm**, the inverse dynamics model receives 21 inputs and outputs 7 torque ... variable q. The **position error** of the ...

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... becomes the model input. The model is illustrated in Figure 2. Fig. 2 . Nonlinear model of the **robot arm**. The damping and the nonlinear ...

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[PDF] **PARAMETER IDENTIFICATION OF A ROBOT ARM USING GENETIC ALGORITHMS**

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"robot arm" and "position error"

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